ABSTRACT

A programming system for a robot comprises a portable programming terminal (6) having a series of jog keys (14) for controlling the motions of the robot, a key (18) for selecting one among a plurality of possible co-ordinate system for the jog keys (14) and a key (21) for storing the position reached by a predefined point of a tool supported by the robot, as a result of a motion thereof. The terminal (6) comprises additional control keys (40, 41), able to be operated manually instead of the jog keys (14), to cause, independently from the co-ordinate system selected with the selection key (18), a Cartesian and/or angular displacement of the predefined point of the tool relative to a reference point that may be varied at will, which corresponds to the position of the operator who uses the terminal (6).

(Figure 2)